ONBOARD CLASSIFICATION OF HYPERSPECTRAL DATA ON THE EARTH OBSERVING ONE MISSION

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ABSTRACT

Remote-sensed hyperspectral data represents significant challenges in downlink due to its large data volumes. This paper describes a research program designed to process hyperspectral data products onboard spacecraft to (a) reduce data downlink volumes and (b) decrease latency to provide key data products (often by enabling use of lower data rate communications systems). We describe efforts to develop onboard processing to study volcanoes, floods, and cryosphere, using the Hyperion hyperspectral imager and onboard processing for the Earth Observing One (EO-1) mission as well as preliminary work targeting the Hyperspectral Infrared Imager (HyspIRI) mission.

***Index Terms*—** onboard spacecraft processing, event detection, volcanism, surface water detection, cryosphere[']

1. INTRODUCTION

We describe onboard processing algorithms for volcano, flood, and cryosphere analysis deployed onboard the Earth Observing One (EO-1) spacecraft and applied to Hyperion hyperspectral data. We also describe ongoing work to develop oceanographic applications for EO-1 as well as follow-on work targeting the HyspIRI mission. In each of these cases we describe the science processing steps as well as the runtime benchmarks for a range of flight processors.

The motivation for onboard processing is multifold. First, many space missions are downlink limited. Onboard processing can dramatically reduce the amount of data that needs to be returned. Second, onboard processing can enable more rapid data production. By processing the data onboard and reducing the data volume it is possible to downlink alerts or summary products via lower data rate engineering downlink – resulting in more rapid notification (an example of this is the Direct Broadcast system [Directbroadcast]). Third, onboard processing can enable onboard response providing more rapid response to science events. For example, EO-1 onboard science analysis can drive retasking the spacecraft - enabling response to science events within hours compared to routine ground-in-the-loop data processing and response of one week or rush ground response of several days.

2. THE EARTH OBSERVING ONE MISSION

EO-1 [Ungar et al. 2003]was launched in November 2000 into a 705-km circular orbit with an inclination of 98.7 degrees. This orbit affords global coverage, with exact ground-repeat tracks every 16 days. EO-1 is a pointable spacecraft. Observations can be nadir, one path to the east or west, and two paths to the east or west. A target may therefore be imaged up to 10 times in any 16-day period, with five day and five night observations. For polar targets, where orbital paths converge, imaging up to five paths away from the nadir is theoretically possible.

On board EO-1 are three instruments: the Advanced Land Imager (ALI), the LEISA Atmospheric Corrector (LAC) and the Hyperion imaging spectrometer. ASE uses data from the Hyperion instrument although an effort is underway to enable onboard access to ALI data.

The Hyperion imaging spectrometer is a hyperspectral imager with 220 discrete bands covering a wavelength range of 0.4–2.5 μm. This spectral range makes Hyperion an excellent instrument for tracking many science phenomena that can be distinguished with these spectra. Hyperion has a spatial resolution of 30 m/pixel. A typical Hyperion observation is 7.7 km (256 pixels) wide by 95km (3176 pixels) long.

3. THE AUTONOMOUS SCIENCECRAFT

The Autonomous Sciencecraft Experiment (ASE) [Chien et al. 2005] is flight software that has been the primary means of operating the EO-1 mission since 2004. ASE has science processing, mission planning, and onboard execution

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components. The science processing component enables onboard analysis of Hyperion imagery to develop smaller products for rapid downlink, downlink of alerts, and to drive onboard decision-making. The onboard mission planning component enables EO-1 to change future observations based on detected events. The onboard execution component executes the mission plans and enables the overall system to be robust to run-time variances.

The ASE software has been operating the EO-1 spacecraft since 2004 and has successfully acquired over 20,000 images under software control. For further information on ASE see [Chien et al. 2005]. This paper focuses on the onboard science element of ASE because the onboard science element processes Hyperion hyperspectral data onboard EO-1.

4. ONBOARD PROCESSING OF HYPERSPECTRAL HYPERION DATA ON EO-1

As part of the ASE software we do onboard processing of 3 event types: thermal detection and summarization to enable volcano science; flood classification of surface water to enable flood science; and snow water ice land (SWIL) classification to enable cryosphere science. The onboard science algorithm can extract 12 selectable bands of the 220 Hyperion bands for a patch of 256 wide by 1024 long pixels. In the following sections we describe these hyperspectral data analysis algorithms in greater detail.

4.1. Thermal Classification and Summarization

EO-1 is flying an onboard thermal detection and summarization algorithm [Davies et al. 2006]. This algorithm uses the infra-red bands of the Hyperion instrument to evaluate images for very hot (over 400 Kelvin) signatures. The thermal processing algorithms use a spectral gradient measure[1] G = (2.28 μm - 1.65 μm)/(2.28 – 1.65) as well as a number of other thermally sensitive bands as shown below.

Description	Measure
H1: Hot radiance minimum and pixel not noisy	0.625 < 1.65 μm, 2.25 μm, & 2.28 μm < 750
H2: Min. slope for trigger?	Slope G > 0.13558 G=1.4 for DNs
H3/E3: No 2.28μm spike	(2.28μm+1.65μm)/2<2.25μm*1.2
E1: Extreme radiance min.?	0.625 < 1.25 μm, 1.65 μm, & 2.28 μm < 750
E2: Spectrum shape	2.28 μm > 1.65 μm/2

The onboard thermal classification algorithm finds all pixels matching conditions H1, H2, & H3 listed above and labels them as "HOT". All remaining pixels that satisfy conditions E1, E2, and E3 are labeled as "EXTREME". The thermal algorithm downlinks a map of the hot and extreme pixels as well as the extracted 12 spectral bands of the hot and extreme pixels (of requested). Because the data allocation for the summary algorithms is limited if there are too many hot and extreme pixels only the first N will be downlinked. Figure 1 shows sample thermal products.

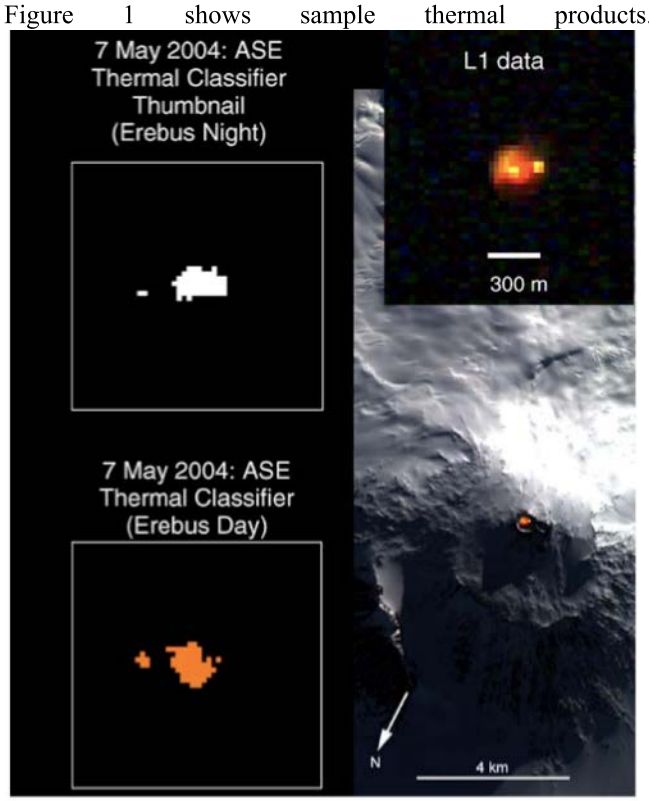

Figure 1: Hot and extreme pixel classification maps as well as Level One full data for EO-1/ASE trigger and autonomous response data acquired of the Mount Erebus volcano 7th May 2004 on two overflights. Figure courtesy [Davies et al. 2006].

4.2. Flood Classification

The onboard flood classification algorithm is intended to enable onboard recognition of major flooding events [Ip et al. 2006]. Through iterative analysis of data from test sites two algorithms were developed for a range of sediment loads. The first of these flood detection algorithms uses the ratio of 0.55 μm / 0.86 μm Hyperion data. The second utilizes the ratio between the 0.99 μm / 0.86 μm data. One complication in utilizing the flood classifier is accurate estimation of cloud cover for masking the flood scene as clouds are also H_2O and thus likely to be classified as surface water. In order to address this issue prior to flood detection the images are screened for clouds using a cloud classifier developed by MIT Lincoln Laboratory [Griffin et

[1] Throughout this paper we use x.yy μm the shorthand for the intensity at x.yy μm.

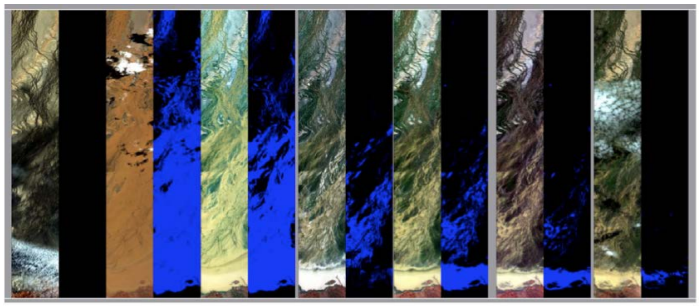

Figure 2: Diamantina flooding sequence. False color and classified scenes of prime sites (256×1024 pixels/7.7km×30km center subset of a Hyperion scene) along the Diamantina River, Australia (1/5/04, 1/30/04, 2/6/04, 2/13/04, 2/15,04, 2/22/04 and 2/29/04). This figure demonstrates the EO-1's 16-day-repeat cycle is sufficient to capture the onset and retreat of a flood event such as this one. Figure courtesy [Ip et al. 2006]

al. 2003]. Figure 2 shows a sequence of Hyperion flood scenes with the corresponding derived classification maps.

4.3. Cryosphere Classification

EO-1 and ASE also demonstrated onboard classification of Snow, Water, Ice, and Land (SWIL). A classifier was manually derived [Doggett et al. 2006] and later a Support Vector Machine (SVM) algorithms was automatically learned by training on expert labeled data. The manual algorithm is shown below - Figure 3 shows the details of the algorithm, and Figure 4 shows a sequence of Hyperion images and derived classification. The cryosphere algorithm uses the Normalized Difference Snow Index (NSDI) defined as NSDI = (0.56μm – 1.65μm)/(0.56μm+1.65μm). Another cryosphere classifier was developed using Support Vector Machine (SVM) learning techniques and is described in [Castano et al. 2006].

5. WORK IN PROGRESS

Ongoing work includes development of products for marine applications and benchmarking algorithms on current and future flight processors.

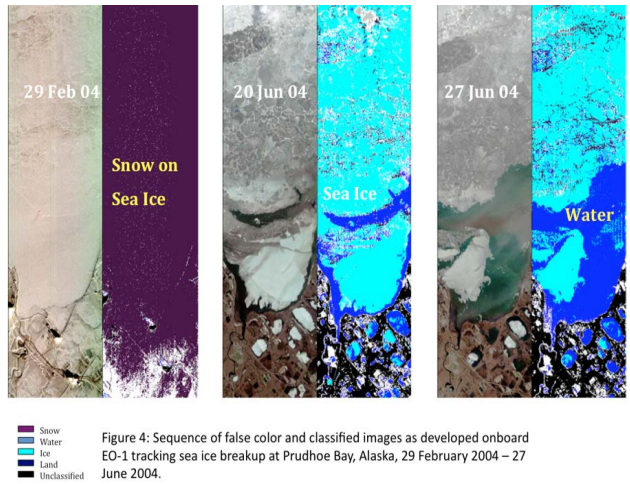

Figure 4: Sequence of false color and classified images as developed onboard EO-1 tracking sea ice breakup at Prudhoe Bay, Alaska, 29 February 2004 – 27 June 2004.

5.1. Marine applications

Ongoing work includes development of rapid products for a range of marine applications. Ground-based processing of marine data for an October 2008 experiment in Monterey Bay [Chien et al. 2009] included acquisition of Hyperion data and delivery of with two derivative science products Fluorescence Line Height (FLH) and Maximum Chlorophyll Index (MCI) linear baseline data products [Gower and Borstad 2004, Gower et al. 2005]. For Hyperion data the FLH and MCI measures were adapted from MODIS definitions: FLH = 681μm – 660μm – 0.4 * (711μm – 660 μm) and MCI = (711μm – 681μm – 0.422 * (752 μm – 660 μm). Figure 5 shows a sample MCI product produced as part of the October 2008 deployment. Development of FLH and MCI products onboard would enable more rapid dissemination of science results for quick response activities (such as issuing alerts or deployment of sensors for further acquisitions).

Description of cryosphere classifier steps in ASE release 3

Step	Algorithm	Classification	Notes
1	If $\rho_{0.86}/\rho_{0.86}>2.23$	Water	Inverse of the standard ratio vegetation index (Tucker, 1979)
2	$\rho_{0.56}/\rho_{0.86}>3.83$	Water	
3	$\rho_{0.56}/\rho_{0.86}<0.8$	Land	
4	$L_{1.65}>62.5$ or $L_{1.65}<0$	Unclassified	Filter for instrument noise, patched in ASE Release 3
5	NDSI<0.176	Unclassified	Cloud not picked up by Griffin et al. (2003), and shadow
6	$\rho_{0.56}/\rho_{0.66}<0.91$	Unclassified	Playa and other bright land lacking vegetation
7	NDSI>0.56 and $\rho_{0.56}/\rho_{0.66}<1.11$		
7a	$\rho_{0.56}/\rho_{0.66}<1$	Snow	
7b	$\rho_{0.86}/\rho_{1.65}>16$	Unclassified	Cloud not picked up by Griffin et al. (2003)
7c	$\rho_{0.66}/\rho_{1.65}<5.4$	Unclassified	Cloud not picked up by Griffin et al. (2003)
7d	$\rho_{0.66}/\rho_{0.86}>1.2$	Ice	Remaining pixels from step 7 are classified as snow
8	NDSI<0.56 and $\rho_{0.56}/\rho_{0.66}<1.064$	Unclassified	Cloud not picked up by Griffin et al. (2003)
9	NDSI<0.47 and $\rho_{0.56}/\rho_{0.66}>1.76$	Water	
10	$\rho_{0.43}/\rho_{0.56}<1.37$		
10a	$\rho_{0.86}/\rho_{1.65}>1.4$	Ice	Modified by patch in ASE Release 2 (see text)
10b	$\rho_{0.43}/\rho_{0.86}>2.65$	Water	Remaining pixels from step 10 are left as unclassified (clouds not picked up by Griffin et al. (2003
11	NDSI<0.27	Cloud	
12	$(\rho_{0.86}-\rho_{1.65})/(\rho_{0.86}+\rho_{1.65})>0.71$	Unclassified	Cloud not picked up by Griffin et al. (2003), and shadow
13	$\rho_{0.56}/\rho_{0.66}>1.376$	Water	
14	$\rho_{0.43}/\rho_{0.56}>1.73$	Unclassified	Shadows, all remaining pixels are classified as water

Figure 3: Cryosphere Snow Water Ice Land (SWIL) manually derived classification algorithm (courtesy [Doggett et al. 2006]).

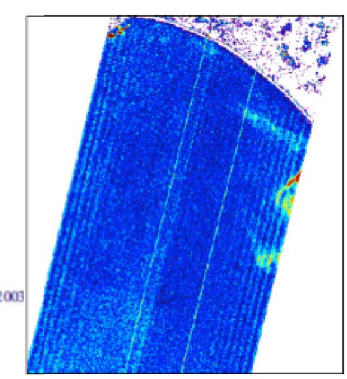

Figure 5: False color Maximum Chlorophyll Index derived from Hyperion imagery of Monterey Bay acquired 21 October 2008. (courtesy MBARI)

5.2. HyspIRI

Ongoing experiments and analysis of onboard processing are targeted at evaluating onboard processing for potential use in the HyspIRI mission – a future mission under evaluation by NASA with hyperspectral imaging capability [Green et al. 2008]. These studies include testing the above algorithms as well as algorithms aimed at tracking drought and plant stress on a range of flight processors including the Mongoose M5 (currently flying on EO-1), Electra, Rad 750, as well as more powerful FPGA based platforms. Currently the thermal algorithm takes 5 minutes, cloud takes 5-10, SWIL 40-50 minutes, and flood 30-40 minutes onboard EO-1 running on the M5 (with onboard science processing getting ~ 40% of the CPU due to other FSW).

6. RELATED WORK AND CONCLUSIONS

Other work has studied the use of Support Vector Machine (SVM) learning techniques to onboard detection of active sulfur springs [Mandrake et al, 2009]. This work includes analysis of linear, polynomial, and gaussian kernel SVM's to detection of sulfur in Hyperion images – a very challenging task due to the slight sulfur signature (sub pixel) and limited onboard computing on EO-1. Onboard data analysis algorithms have also been developed for the THEMIS instrument onboard Mars Odyssey [Castano et al. 2007] but as of yet have not been integrated with the flight software or uploaded and used. The Mars Exploration Rovers now have the ability to analyze onboard imagery to detect dust devils and clouds [Castano et al. 2008, Chien et al. 2008] and a further upload is under way to enable autonomous targeting of remote science instruments onboard MER [Estlin et al. 2009].

We have described a number of algorithms intended for classification of hyperspectral images onboard spacecraft. The thermal event detection and summarization, surface water/flood detection, and snow/water/ice/land cryosphere tracking have been operational onboard the EO-1 spacecraft processing Hyperion data since 2004. We then described ongoing work towards onboard algorithms including marine science products. Onboard production of these science products enables: (1) more rapid delivery of science products and (2) more rapid response to acquire further imagery, issue alerts, or other actions.

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